

## CLAIM AMENDMENTS:

1-11 cancelled

12. (new) A method for calibrating a camera-laser-unit with respect to at least one calibration-object disposed at a given position and orientation in three-dimensional space, the camera-laser-unit having at least one laser and at least one camera, wherein the laser and the camera are disposed at a given distance with respect to one another, and an optical axis of the laser and an optical axis of the camera subtend a given angle ( $\alpha$ ), the camera-laser-unit being adapted to record a location, shape and/or dimensions of a measurement-object, the method comprising the steps of:
- a) selecting a calibration-object having at least two planes disposed at a given angle ( $\beta$ ) with respect to each other, each plane having a given, non-coplanar calibration-pattern;
  - b) disposing the calibration-object at a given position and orientation in three-dimensional space with respect to the camera-laser-unit, wherein an orientation of the calibration-object is such that light emitted by the laser is visible to the camera on the at least two planes of the calibration-object;
  - c) calibrating the camera with respect to the calibration-object using a Tsai algorithm;
  - d) activating the laser to emit light visible on the at least two planes of the calibration-object;
  - e) recording the light on the two planes with the camera;

- f) determining the laser-properties from the light recorded by the camera; and
  - g) calibrating the laser according to the determined laser-properties.
- 13. (new) The method of claim 12, wherein step g) comprises the step of defining a relative position and orientation of the laser with respect to a coordinate frame associated with the calibration-object, wherein the coordinate frame has a given position and orientation in three-dimensional space.
- 14. (new) The method of claim 12, wherein light emitted by the laser is visible on the two planes of the calibration-object as a line on each plane, the lines intersecting at a contact line of the two planes, wherein the laser-properties are determined from the lines recorded by the camera using a line detection algorithm.
- 15. (new) The method of claim 12, wherein light emitted by the laser is visible on the two planes of the calibration-object as a line on each plane, the lines intersecting at a contact line of the two planes, wherein a laser-plane is defined by an optical axis of the laser and the lines visible on the two planes of the calibration-object, wherein, a position and orientation of the laser-plane with respect to a coordinate frame associated with the calibration-object is defined to calibrate the laser according to determined laser-properties.
- 16. (new) The method of claim 12, wherein step c) comprises the step of defining a relative position and orientation of the camera with respect to a coordinate frame associated with the calibration-object, said

coordinate frame having a given position and orientation in three-dimensional space.

17. (new) The method of claim 12, further comprising defining a transformation matrix in dependence on a relative position and orientation of the camera with respect to a coordinate frame associated with the calibration-object, a relative position and orientation of the laser with respect to the coordinate frame, and/or on internal camera parameters.
18. (new) The method of claim 12, further comprising grasping the camera-laser-unit with an industrial robot and disposing the unit relative to the calibration-object in a given position and orientation in three-dimensional space, wherein an orientation of the camera-laser-unit is such that light emitted by the laser is visible to the camera on the at least two planes of the calibration-object.
19. (new) A calibration-object for calibrating a camera-laser-unit the calibration object being disposed at a given position and orientation in three-dimensional space, the camera-laser-unit having at least one laser and at least one camera, the laser and the camera being disposed at a given distance, wherein an optical axis of the laser and an optical axis of the camera subtend a given angle ( $\alpha$ ) and the camera-laser-unit is structured to record a location, shape and/or dimensions of a measurement-object, the calibration object comprising:

two planes disposed at a given angle with respect to each other, each plane having a non-coplanar, calibration-pattern

with an array of features, wherein the calibration-object is structured and dimensioned for calibration of the camera as well as for calibration of the laser.

20. (new) The calibration-object of claim 19, wherein said angle between said two planes of the calibration-object is a right angle.
21. (new) The calibration-object of claim 19, wherein features of said calibration-pattern are designed as recesses or as cavities having a circular cross section.
22. (new) The calibration-object of claim 19, wherein features of said calibration-pattern comprise prints on said two planes.